In the Claims:

Please amend the claims as follows:

1. (currently amended) A robot wrist for an industrial robot, said robot wrist comprising:

a wrist housing;

a wrist tilt part journalled at the wrist housing, wherein the tilt is rotatable relative to the wrist housing about an axis of ~~rotation; and~~ rotation, the wrist tilt comprising a drive unit comprising a motor with a motor housing, the motor housing comprising a shell part designed to connect the tilt to the wrist housing, wherein the motor comprises a stator and a rotor arranged in the motor housing such that the motor housing surrounds the stator, wherein the motor housing comprises an opening adapted to allow insertion of the stator into the motor housing, and wherein the motor housing comprises a sealing member adapted to seal the opening.

2. (previously amended) The robot wrist according to claim 1, wherein the tilt comprises a first part that is rotatable relative to the wrist housing about a first axis of rotation, and a second part that is connected to the first part and designed to support a toolholder and that is rotatable relative to the first part about a second axis of rotation.

3. (previously amended) The robot wrist according to claim 2, wherein the drive unit is arranged for rotation of the second part relative to the first part about the second axis of rotation.

4. (previously amended) The robot wrist according to claim 1, wherein the drive unit is

arranged for rotation of the tilt relative to the wrist housing.

5. (previously amended) The robot wrist according to claim 1, wherein the outside of the shell part is designed to connect the tilt to the wrist housing.

6. (cancelled)

7. (previously amended) The robot wrist according to claim 1, wherein the stator makes contact with the shell part.

8. (previously amended) The robot wrist according to claim 7, wherein the stator makes contact with an inside of the shell part.

9. (previously amended) The robot wrist according to claim 8, wherein the inside of the shell part comprises a shoulder, wherein the stator makes contact with the shoulder to prevent displacement of the stator in an axial direction relative to the motor housing.

10. (cancelled)

11. (previously amended) The robot wrist according to claim 1, wherein the sealing member comprises a front portion adapted to be received inside the shell part.

12. (previously amended) The robot wrist according to claim 9, wherein the stator is

clamped between the front portion of the sealing member and the shoulder of the shell part.

13. (previously amended) The robot wrist according to claim 1, wherein an outside of the shell part comprises at least one fixing member, and wherein the wrist housing comprises at least one fixing member that is rigidly connected to a corresponding one of the at least one fixing member on the shell part.

14. (previously amended) The robot wrist according to claim 13, wherein the at least one fixing member of the shell part comprises a recess, and wherein the at least one fixing member of the wrist housing comprises a shaft journal received in said recess, or vice versa.

15. (previously amended) The robot wrist according to claim 13, wherein the at least one fixing member of the shell part and the corresponding one of the at least one fixing member of the wrist housing make contact with each other via mutual contact surfaces, whereby the contact surfaces comprise countersunk and/or raised portions adapted to engage with each other to transmit a rotary force between the fixing members.

16. (previously amended) The robot wrist according to claim 13, wherein the shell part comprises two fixing members on essentially opposite sides of the shell part.

17. (previously amended) The robot wrist according to claim 1, wherein the robot wrist is designed for a maximum handling weight of at least 100 kg.

18. (currently amended) An industrial robot, comprising:

a robot wrist comprising

a wrist housing,

a wrist tilt part journalled at the wrist housing, wherein the tilt is rotatable relative to the wrist housing about an axis of rotation, ~~and~~ the tilt comprising a drive unit comprising a motor with a motor housing, the motor housing comprising a shell part designed to connect the tilt to the wrist housing, wherein the motor comprises a stator and a rotor arranged in the motor housing such that the motor housing surrounds the stator, wherein the motor housing comprises an opening adapted to allow insertion of the stator into the motor housing, and wherein the motor housing comprises a sealing member adapted to seal the opening.

19. (previously amended) A tilt adapted to be journalled in a wrist housing of a robot wrist for an industrial robot, wherein the tilt is rotatable relative to the wrist housing about an axis of rotation, the tilt comprising:

a drive unit comprising a motor with a motor housing, wherein a shell part of the motor housing is designed to connect the tilt to the wrist housing.

20. (previously amended) The tilt according to claim 19, further comprising

a first part that is rotatable relative to the wrist housing about a first axis of rotation, and

a second part that is connected to the first part and is designed to support a toolholder and that is rotatable relative to the first part about a second axis of rotation.

21. (previously amended) The tilt according to claim 20, wherein the drive unit is adapted for rotation of the second part relative to the first part about the second axis of rotation.

22. (previously amended) The tilt according to claim 19, wherein the drive unit is adapted for rotation of the tilt relative to the wrist housing.